

**AMENDMENTS TO THE CLAIMS**

1-11. (Canceled)

12. (New) A self-propelled working robot comprising:

a traveling assembly having a wheel rotating on a floor surface;

a working assembly for doing work on the floor surface, wherein the working assembly is attached to the traveling assembly so that the working assembly is movable in a left-right direction with respect to the traveling assembly;

a moving mechanism for moving the working assembly with respect to the traveling assembly so as to change a positional relationship between the traveling assembly and the working assembly;

a first contact sensor provided in the working assembly for detecting a contact of the obstacle with a front surface of the working assembly;

a second contact sensor provided in the working assembly for detecting a contact of the obstacle with a side surface of the working assembly; and

means for controlling a travel of the traveling assembly, for controlling the moving mechanism to move the working assembly left and right at a first retraction speed based on a detection signal from the first contact sensor, and for controlling the moving mechanism to move the working assembly left and right at a second retraction speed, being lower than the first retraction speed, based on a detection signal from the second contact sensor.

13. (New) A self-propelled working robot according to claim 12, wherein the control means further comprises means for stopping the travel when a time for which a contact is being detected by the first contact sensor is longer than a predetermined time (H).

14. (New) A self-propelled working robot according to claim 13, wherein the predetermined time (H) is set to a small value when a traveling speed is high, and is set to a large value when the traveling speed is low.